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ABSTRACT OF THE DISCLOSURE/

Out a2. A target tracking device for target tracking missiles has an electro-optical seeker assembly mounted in/a missile structure (10) through gimbals. The seeker assemb∤y responds to target radiation and provides target deviation signals. Actuators cause the seeker assembly to track the target. The actuators are controlled by the target deviation signals. The electrooptical seeker assembly is pivotally mounted in the missile structure about a roll axis and a pitch axis (20) only, the pitch axis being orthogonal to the roll axis. First and second are provided for picking off angles of rotation of the seeker assembly about the roll and pitch axes. The first and second pick-offs provide pick-off signals. A structurefixed inertial sensor unit is provided for measuring three mutually orthogonal angular rates about providing angular rate signals. The target deviation signals from the seeker assembly, the/pick-off signals from the pickoffs and the angular rate stignals from the inertial sensor unit are appied to a computer, which is programmed to define a seeker reference system with three degrees of freedom. This seeker reference system is de-coupled from movements of the missile and the seeker assembly. The roll movement of the seeker reference system is zero. The seeker reference system is caused to track a target detected by the seeker assembly. The computer, in addition, generates positioning commands for actuators depending on the position of the reference system. The device for generating the positioning command is a case discriminating logic for selecting one of a plurality of specific positioning commands, when the target approaches the roll axis.

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